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1	BRS	L1	7	IOL and transla\$ adj3 axis	į	2004/01/ 14 10:59	:
2	BRS	L2	14	IOL and transla\$ adj5 axis	:	2004/01/ 14 11:14	<u> </u>
3	BRS	L3		IOL and transla\$ same axis and ciliar\$	•	2004/01/ 14 11:21	
4	BRS	L4	1	6013101.pn.		2004/01/ 14 11:21	
5	BRS	L5	1	6013101.pn. and axis		2004/01/ 14 11:22	
6	BRS	L6		6013101.pn. and axis same m v \$		2004/01/ 14 11:22	
7	BRS	L7	1	6013101.pn. and axis same move\$ and transla\$		2004/01/ 14 11:53	

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	Err r Definiti n	Er r rs
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2		0
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8	BRS	L8	1	6013101.pn. and material\$		2004/01/ 14 11:54	
9	BRS	L9	O	6013101.pn. and (metal or shape adj3 memor\$)		2004/01/ 14 11:54	
10	BRS	L10	1	6013101.pn. and manufac\$		2004/01/ 14 11:55	
11	BRS	L11	0	6013101.pn. and made adj3 from		2004/01/ 14 11:55	
12	BRS	L12	0	6013101.pn. and made adj3 of		2004/01/ 14 12:00	
13	BRS	L13	1	6013101.pn. and bias\$	USP AT	2004/01/ 14 12:00	

	Error Definiti n	Er ro rs
8		0
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13		0

termediate the first and second positions.

Brief Summary Text - BSTX (9):

U.S. Pat. No. 6,013,101 discusses the difference between what it calls

"rigid" haptics or linkage arms and "flexible" or "resilient" haptics.

Resilient haptics comprise resilient wires formed of plastics or any other

biologically inert material, which are sufficiently stiff so that when a

compressive force is applied thereto, they distort but do not buckle or

collapse. When compressed, resilient haptics cause the artificial lens to

translate anteriorly along the optical axis

(anterior-posterior axis). When

the compressive force is reduced, the resilient haptics spring back under their

own elasticity so as to return the lens to its original position.

Brief Summary Text - BSTX (13):
The present invention seeks to